

1 1. A method for constructing a first image and a second image of an omnivergent
2 stereo image pair, comprising:
3 rotating a deflector about a rotation axis, the deflector positioned a distance from
4 the rotation axis and having plural deflection regions;
5 positioning a receptor proximate to the rotation axis, the receptor comprising a
6 first portion of sensors and a second portion of sensors;
7 deflecting a first input received at a first deflection region of the deflector to the
8 first portion of sensors;
9 deflecting a second input received at a second deflection region of the deflector
10 to a second portion of sensors;
11 determining the first image based at least in part on the first input;
12 determining the second image based at least in part on the second input; and
13 determining a first omnivergent stereo pair based at least in part on the first
14 image and the second image.

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16 2. The method of claim 1, further comprising:
17 wherein both the first image and the second image are omnivergent images.

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19 3. The method of claim 1, further comprising:
20 selecting a view point; and
21 rendering a three dimensional image based at least in part on the view point
22 and the first omnivergent stereo pair.
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1 4. The method of claim 1, wherein the distance is fixed.

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3 5. The method of claim 1, further comprising:

4 performing the method at a first location to determine the first omnivergent stereo
5 pair;

6 performing the method at a second location to determine a second omnivergent
7 stereo pair; and

8 synthesizing an environment model based at least in part on the first omnivergent
9 stereo pair and the second omnivergent stereo pair.

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12 6. The method of claim 5, wherein the first location is proximate to the
13 second location.

14 7. The method of claim 5, wherein a first region defined by rotating the
15 deflector about the axis at the first location abuts a second region defined by rotating
16 the deflector about the axis at the second location.
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18 8. The method of claim 1, further comprising:

19 receiving a configuration input; and

20 setting the distance with respect to the configuration input.
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22 9. The method of claim 8, wherein the configuration input corresponds to a
23 desired size for a region in which a viewpoint may be selected.

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2 10. The method of claim 9, further comprising:

3 receiving a viewpoint selection; and

4 rendering a three dimensional image based on the viewpoint selection and the
5 first and the second image.

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7 11. A method for constructing an omnivergent stereo image pair, comprising:

8 defining a cylindrical region having an axis of rotation perpendicular to a rotation
9 plane, the cylindrical region defined with respect to an array of sensors disposed

10 parallel to the axis of rotation, and a prism disposed parallel to the vertical array; and
11 determining an environment about the cylindrical region by rotating the cylindrical
12 region through rotational positions, and while rotating:

13 receiving a first input at a first face of the prism for a rotational position of
14 the cylindrical region, the first input having a first travel path tangential to the cylindrical
15 region and corresponding to a first portion of the environment, and

16 receiving a second input at a second face of the prism for the rotational
17 position of the cylindrical region, the second input having a second travel path tangential
18 to the cylindrical region and corresponding to a second portion of the environment.

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20 10. The method of claim 9, further comprising:

21 storing the first input and the second input for each of plural rotational positions
22 of the cylindrical region;

23 selecting a view point within the cylindrical region; and

1 constructing a convergent stereo image of the environment with respect to the
2 selected view point and the stored first and second inputs for the plural rotational
3 positions of the cylindrical region.

4 *13*
5 11. The method of claim 9, wherein the first travel path is opposite of the
6 second travel path.

7 *14*
8 12. The method of claim 9, wherein the first and second travel paths are
9 parallel to the rotation plane.

10 *15*
11 13. An article of manufacture, comprising:
12 a machine accessible medium having associated data, which when accessed by
13 the machine, results in the machine performing:

14 rotating a deflector rotably mounted a distance from a rotation axis, the
15 deflector having plural deflection regions for deflecting inputs to a receptor positioned
16 proximate to the rotation axis, the receptor comprising a first portion of sensors and a
17 second portion of sensors;

18 determining the first image based at least in part on a first input received
19 at a first deflection region of the deflector that is deflected towards the receptor;

20 determining the second image based at least in part on a second input
21 received at a second deflection region of the deflector that is deflected towards the
22 receptor;

1 determining a first omnivergent stereo pair based at least in part on the
2 first image and the second image.

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4 14. The apparatus of claim 13, wherein both the first image and the second
5 image are omnivergent images.

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7 15. The apparatus of claim 13, QQQ:
8 selecting a view point; and
9 rendering a three dimensional image based at least in part on the view point
10 and the first omnivergent stereo pair.

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12 16. The apparatus of claim 13, wherein the distance is fixed.

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14 17. The apparatus of claim 13, QQQ
15 performing the method at a first location to determine the first omnivergent stereo
16 pair;

17 performing the method at a second location to determine a second omnivergent
18 stereo pair; and

19 synthesizing an environment model based at least in part on the first omnivergent
20 stereo pair and the second omnivergent stereo pair.

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22 18. The apparatus of claim 17, wherein the first location is proximate to the
23 second location.

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2 ²¹ 19. The apparatus of claim 17, wherein a first region defined by rotating the
3 deflector about the axis at the first location abuts a second region defined by rotating
4 the deflector about the axis at the second location.

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6 ²² 20. The apparatus of claim 13, QQQ:
7 receiving a configuration input; and
8 setting the distance with respect to the configuration input.

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10 ²³ 21. The apparatus of claim 20, wherein the configuration input corresponds to
11 a desired size for a region in which a viewpoint may be selected.

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13 ²⁴ 22. The apparatus of claim 21, QQQ:
14 receiving a viewpoint selection; and
15 rendering a three dimensional image based on the viewpoint selection and the
16 first and the second image.

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18 ²⁵ 23. An apparatus comprising a machine accessible medium having
19 instructions associated therewith for constructing a first image and a second image of a
20 convergent stereo image pair, the instructions capable of directing a machine to
21 perform:

1 defining a cylindrical region having an axis of rotation perpendicular to a rotation
2 plane, the cylindrical region defined with respect to an array of sensors disposed
3 parallel to the axis of rotation, and a prism disposed parallel to the vertical array;

4 determining an environment about the cylindrical region by rotating the cylindrical
5 region through rotational positions, and while rotating:

6 receiving a first input at a first face of the prism for a rotational position of
7 the cylindrical region, the first input having a first travel path tangential to the cylindrical
8 region and corresponding to a first portion of the environment, and

9 receiving a second input at a second face of the prism for the rotational
10 position of the cylindrical region, the second input having a second travel path tangential
11 to the cylindrical region and corresponding to a second portion of the environment.

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13 24. The apparatus of claim 23, the instructions comprising further instructions
14 capable of directing a machine to perform:

15 storing the first input and the second input for each of plural rotational positions
16 of the cylindrical region;

17 selecting a view point within the cylindrical region; and

18 constructing a convergent stereo image of the environment with respect to the
19 selected view point and the stored first and second inputs for the plural rotational
20 positions of the cylindrical region.

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22 25. The method of claim 23, wherein the first travel path is opposite of the
23 second travel path.

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2 26.²⁸ The method of claim 23, wherein the first and second travel paths are
3 parallel to the rotation plane.
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5 27.²⁹ An apparatus for acquiring input for a first image and a second image of a
6 convergent stereo image pair, comprising:

7 a deflector rotably mounted a distance from a rotation axis, the deflector having
8 plural deflection regions;

9 a receptor positioned proximate to the rotation axis, the receptor comprising a
10 first portion of sensors and a second portion of sensors;

11 a first memory for storing a first input received at a first deflection region of the
12 deflector and deflected towards the first portion of sensors; and

13 a second memory for storing a second input received at a second deflection
14 region and deflected towards the second portion of sensors;
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16 28.³⁰ The apparatus of claim 27, further comprising:

17 an image constructor which determines the first image based at least in part on
18 the first input, and the second image based at least in part on the second input.
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20 29.³¹ The apparatus of claim 28, further comprising:

21 an interface for receiving a selected view point; and

22 a renderer for rendering a three dimensional image based at least in part on the
23 selected view point, the first image, and the second image.

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2 30. ³² The apparatus of claim 27, wherein the deflector rotates about the rotation
3 axis, and while rotating, subsequent first and second inputs are received, deflected, and
4 stored in the first memory and the second memory.

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6 31. ³³ The apparatus of claim 27, further comprising:
7 an interface for receiving a configuration input; and
8 setting the distance with respect to the configuration input.

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10 32. ³⁴ The apparatus of claim 31, wherein the configuration input corresponds to
11 a selected one of a desired depth of field for the convergent stereo image, and a
12 desired size for a region in which a viewpoint may be selected.
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